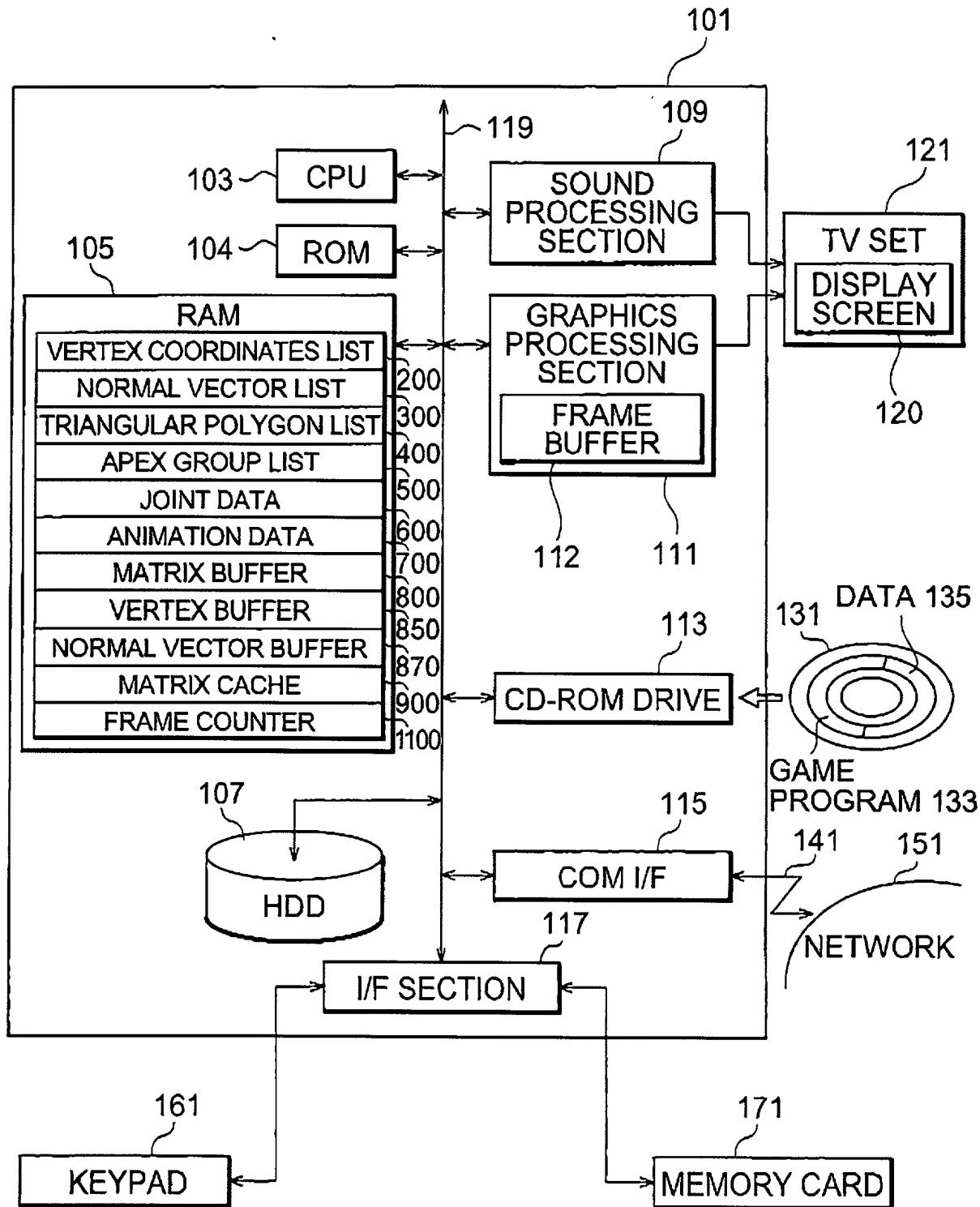
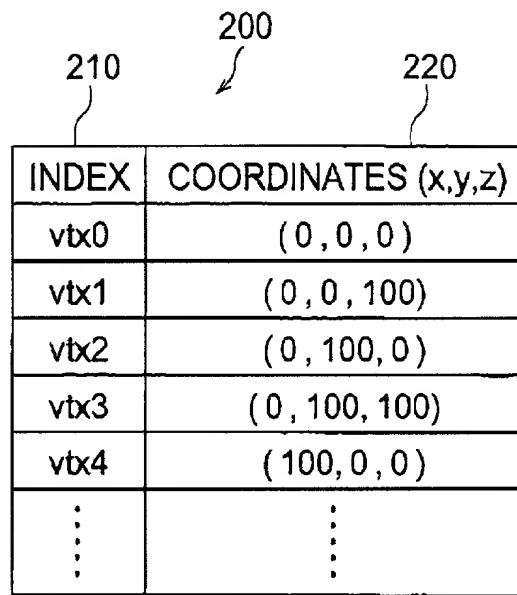


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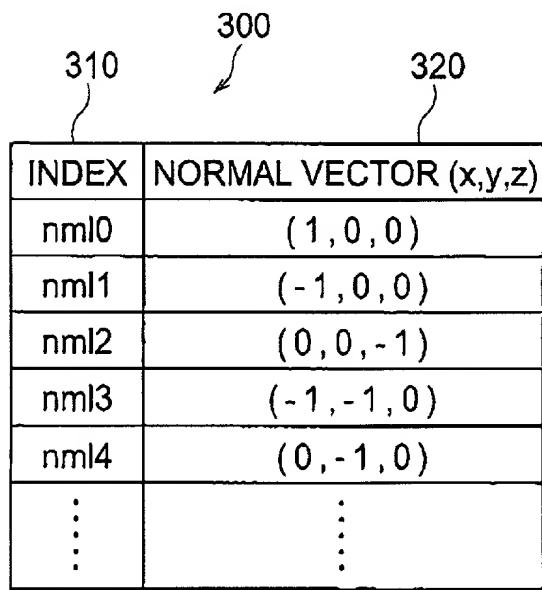
Fig.1



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Fig.2

INDEX	COORDINATES (x,y,z)
vtx0	(0, 0, 0)
vtx1	(0, 0, 100)
vtx2	(0, 100, 0)
vtx3	(0, 100, 100)
vtx4	(100, 0, 0)
⋮	⋮

Fig.3

INDEX	NORMAL VECTOR (x,y,z)
nml0	(1, 0, 0)
nml1	(-1, 0, 0)
nml2	(0, 0, -1)
nml3	(-1, -1, 0)
nml4	(0, -1, 0)
⋮	⋮

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Fig.4

INDEX	VERTEX 0	VERTEX 1	VERTEX 2
plg0	vtx0 / nml0	vtx1 / nml2	vtx2 / nml3
plg1	vtx0 / nml1	vtx2 / nml3	vtx3 / nml4
⋮	⋮	⋮	⋮
⋮	⋮	⋮	⋮

Fig.5

VERTEX GROUP LIST								
510	NUMBER OF GROUPS		3					
520	NUMBER OF MEMBERS		4					
530	VERTEX	vtx1	WEIGHT (540)	1.0	NUMBER OF NORMALS(570)	2	NORMALS (591)	nml0 nml1
532	VERTEX	vtx2	WEIGHT (542)	1.0	NUMBER OF NORMALS(572)	1	NORMALS (592)	nml10
534	VERTEX	vtx3	WEIGHT (544)	1.0	NUMBER OF NORMALS(574)	1	NORMALS (593)	nml2
536	VERTEX	vtx4	WEIGHT (546)	1.0	NUMBER OF NORMALS(576)	2	NORMALS (594)	nml3 nml1
522	NUMBER OF MEMBERS		4					
550	VERTEX	vtx5	WEIGHT (560)	0.5	NUMBER OF NORMALS(580)	1	NORMALS (595)	nml11
552	VERTEX	vtx6	WEIGHT (562)	0.5	NUMBER OF NORMALS(582)	1	NORMALS (596)	nml4
554	VERTEX	vtx7	WEIGHT (564)	1.0	NUMBER OF NORMALS(584)	1	NORMALS (597)	nml5
556	VERTEX	vtx8	WEIGHT (566)	1.0	NUMBER OF NORMALS(586)	3	NORMALS (598)	nml6 nml8 nml9
524	NUMBER OF MEMBERS		1					
558	VERTEX	vtx7	WEIGHT (568)	0.5	NUMBER OF NORMALS(588)	1	NORMALS (599)	nml7

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Fig. 6

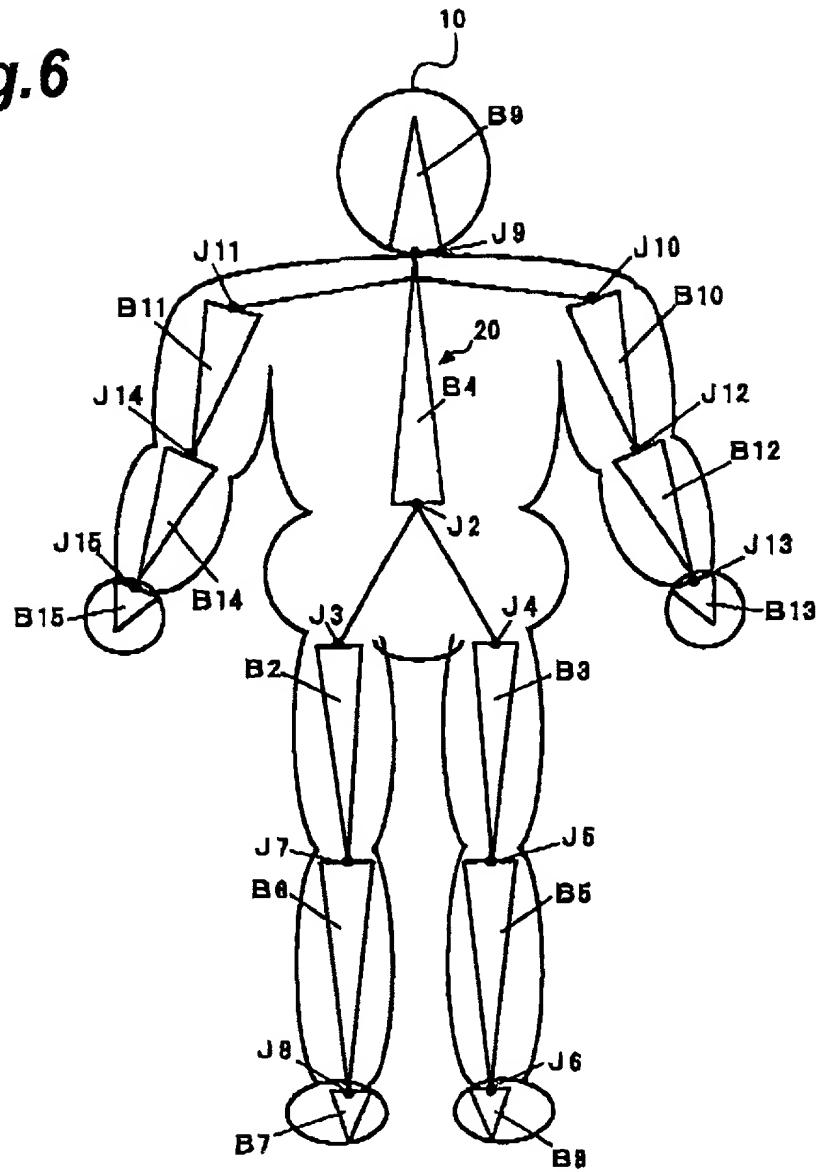
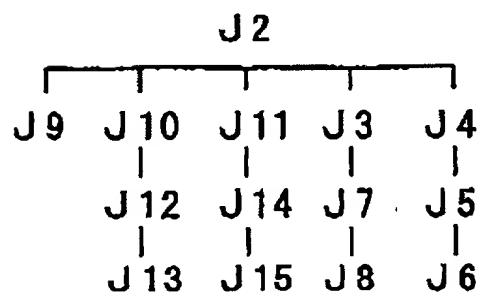


Fig. 7



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Fig.8

Diagram illustrating the structure of a data table 600 representing a 3D model. The table is organized into two main sections: Joint 0 and Joint 1, each with its own set of parameters.

Table 600 Structure:

	Joint 0	Joint 1
610	Root index	root
612	Basic parallel movement amount (x, y, z)	(0, 0, 0)
614	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 90)
616	Number of joints	4
620	Joint index	Joint0
622	Parent index	root
624	Basic parallel movement amount (x, y, z)	(90, 20, 0)
626	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 135)
628	Number of vertex groups	2
630	Vertex group number	0
632	Vertex group number	2
640	Joint index	Joint1
642	Parent index	Joint0
644	Basic parallel movement amount (x, y, z)	(40, 0, 0)
646	Basic Rotation angle (Rx, Ry, Rz)	(0, 0, 45)
648	Number of vertex groups	1
650	Vertex group number	1

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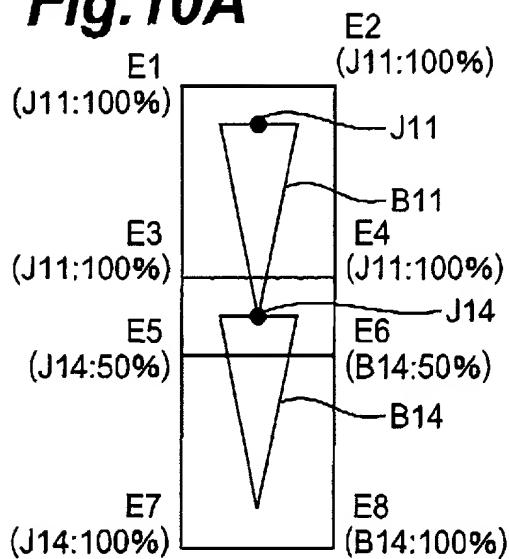
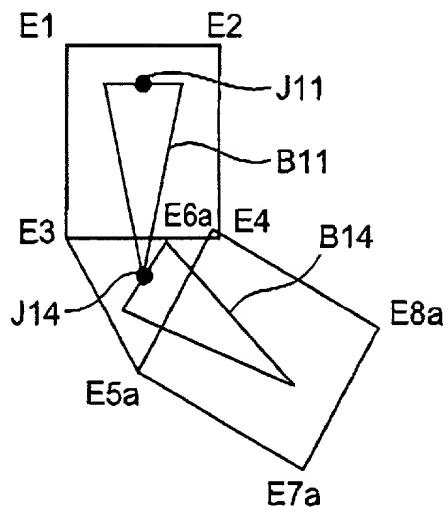
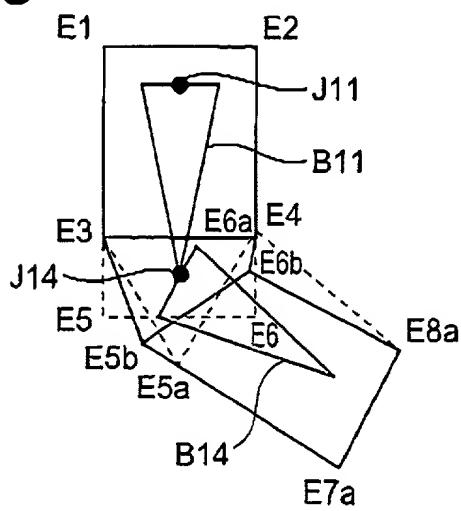
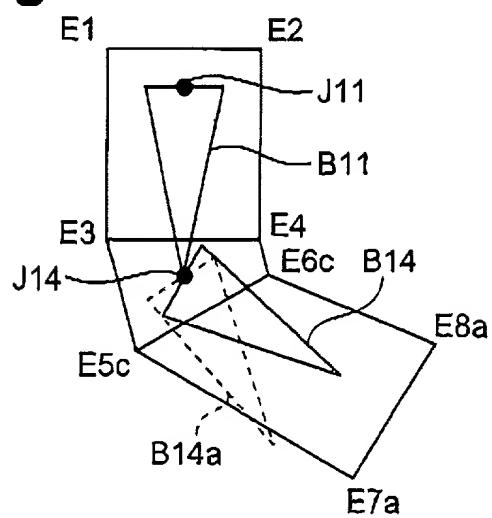
Fig.9A

Number of joints	Number of frames
2	10

Fig.9B

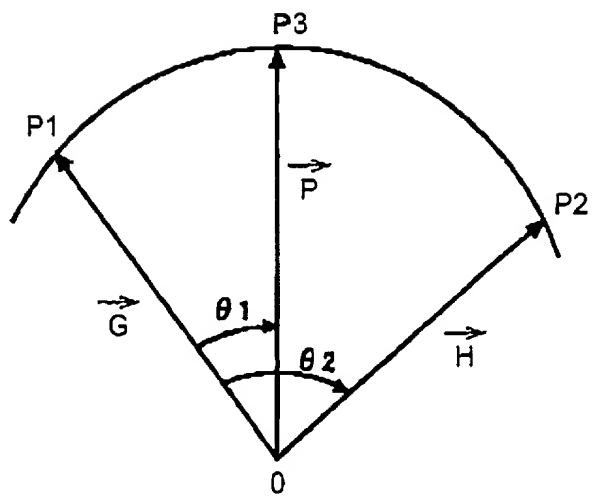
Joint index	Rotation angle (Rx, Ry, Rz)
Joint0	(0, 0, 0)
Joint1	(10, 0, 135)
Joint0	
Joint1	(-10, 5, 45)
Joint0	(90, 0, 150)
Joint1	(-90, 45, 45)

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Fig.10A**Fig.10B****Fig.10C****Fig.10D**

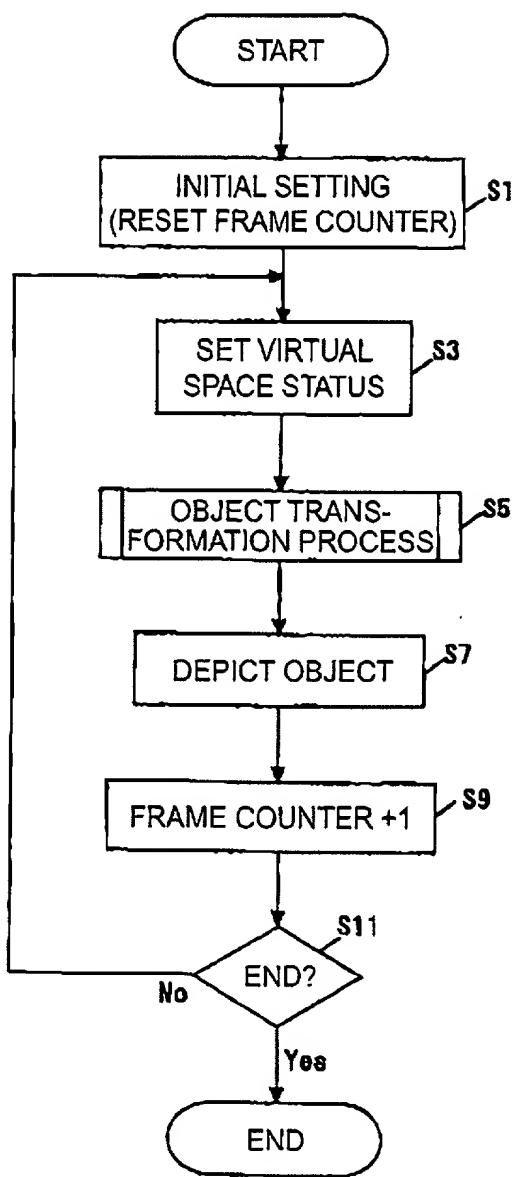
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Fig. 11



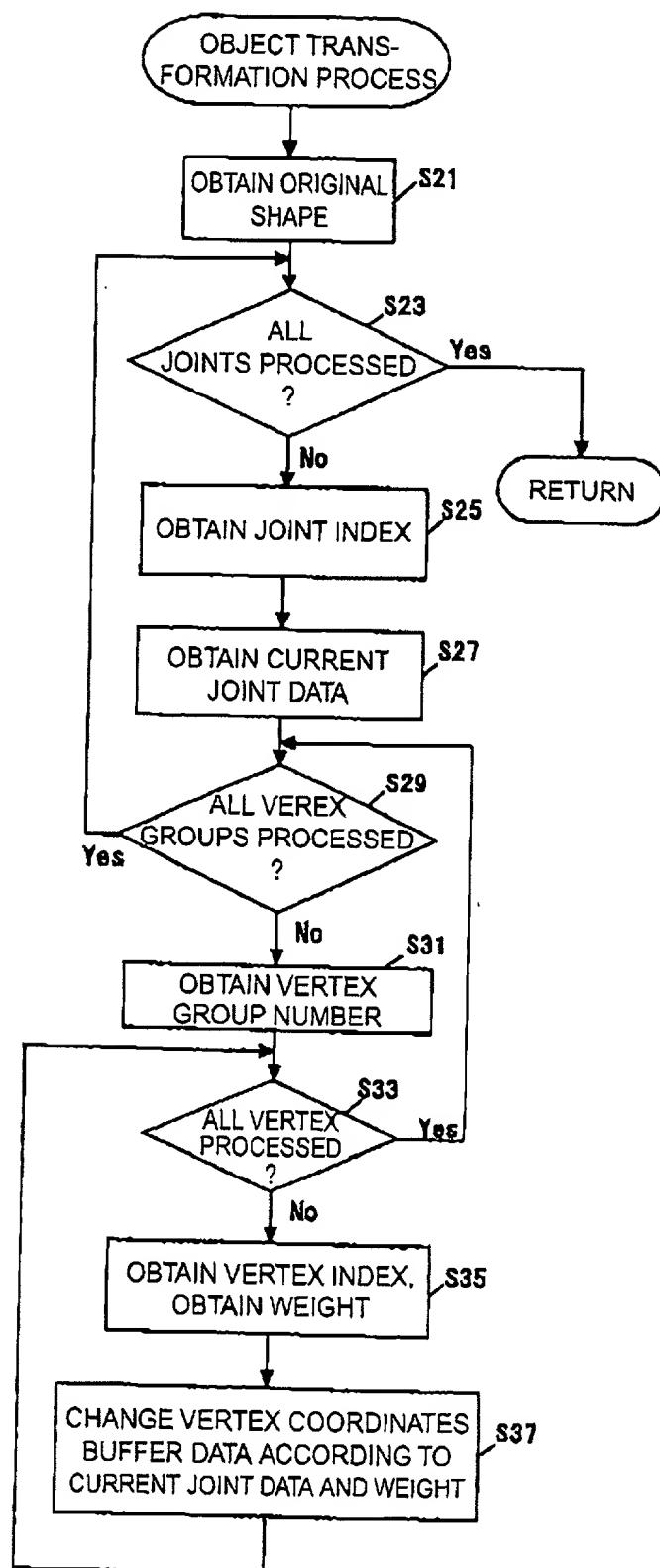
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Fig.12



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Fig.13



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Fig.14

Diagram illustrating a table structure for joint index and matrix data. The table has two columns: 'Joint index' and 'Matrix data'. The 'Joint index' column contains 'root', 'Joint0', and 'Joint1'. The 'Matrix data' column contains 'Root conversion matrix', 'Conversion matrix with 100% weight of joint0', and 'Conversion matrix with 100% weight of joint1'. A pointer labeled 800 points to the 'Matrix data' column. A pointer labeled 810 points to the first row of the 'Joint index' column. A pointer labeled 820 points to the second row of the 'Matrix data' column.

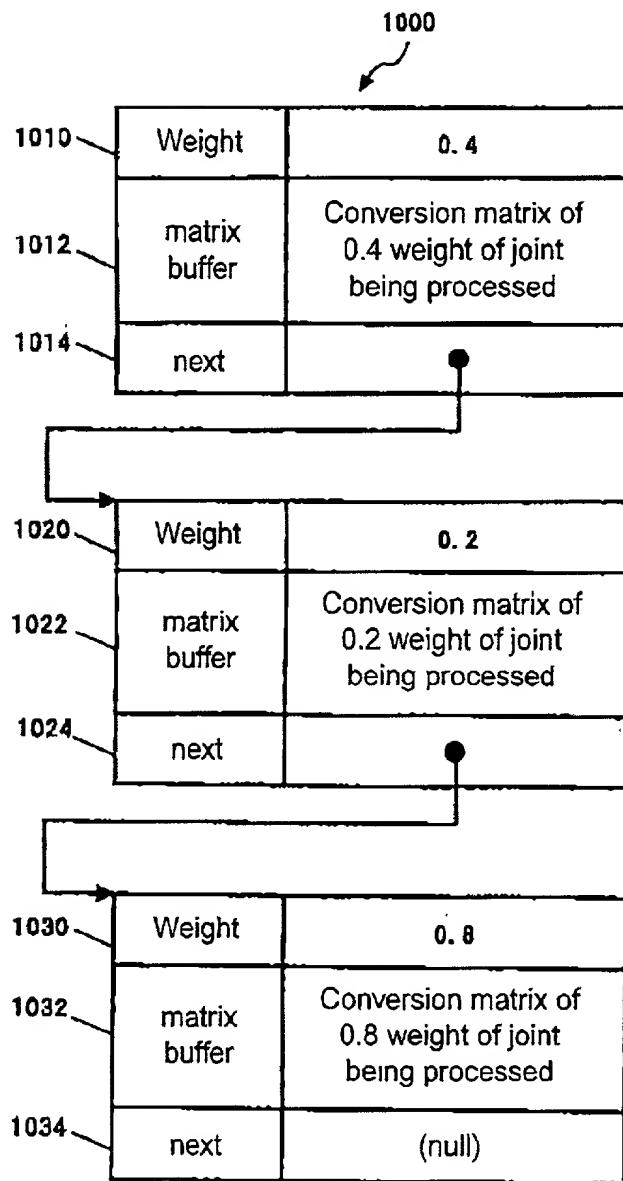
Joint index	Matrix data
root	Root conversion matrix
Joint0	Conversion matrix with 100% weight of joint0
Joint1	Conversion matrix with 100% weight of joint1

Fig.15

Diagram illustrating a table structure for weight and conversion matrix. The table has two columns: 'Weight' and 'Weight'. The 'Weight' column contains 'matrix buffer'. The 'Weight' column contains 'Conversion matrix according to weight of joint being processed'. A pointer labeled 900 points to the 'Weight' column. A pointer labeled 910 points to the first row of the 'Weight' column. A pointer labeled 920 points to the second row of the 'matrix buffer' column.

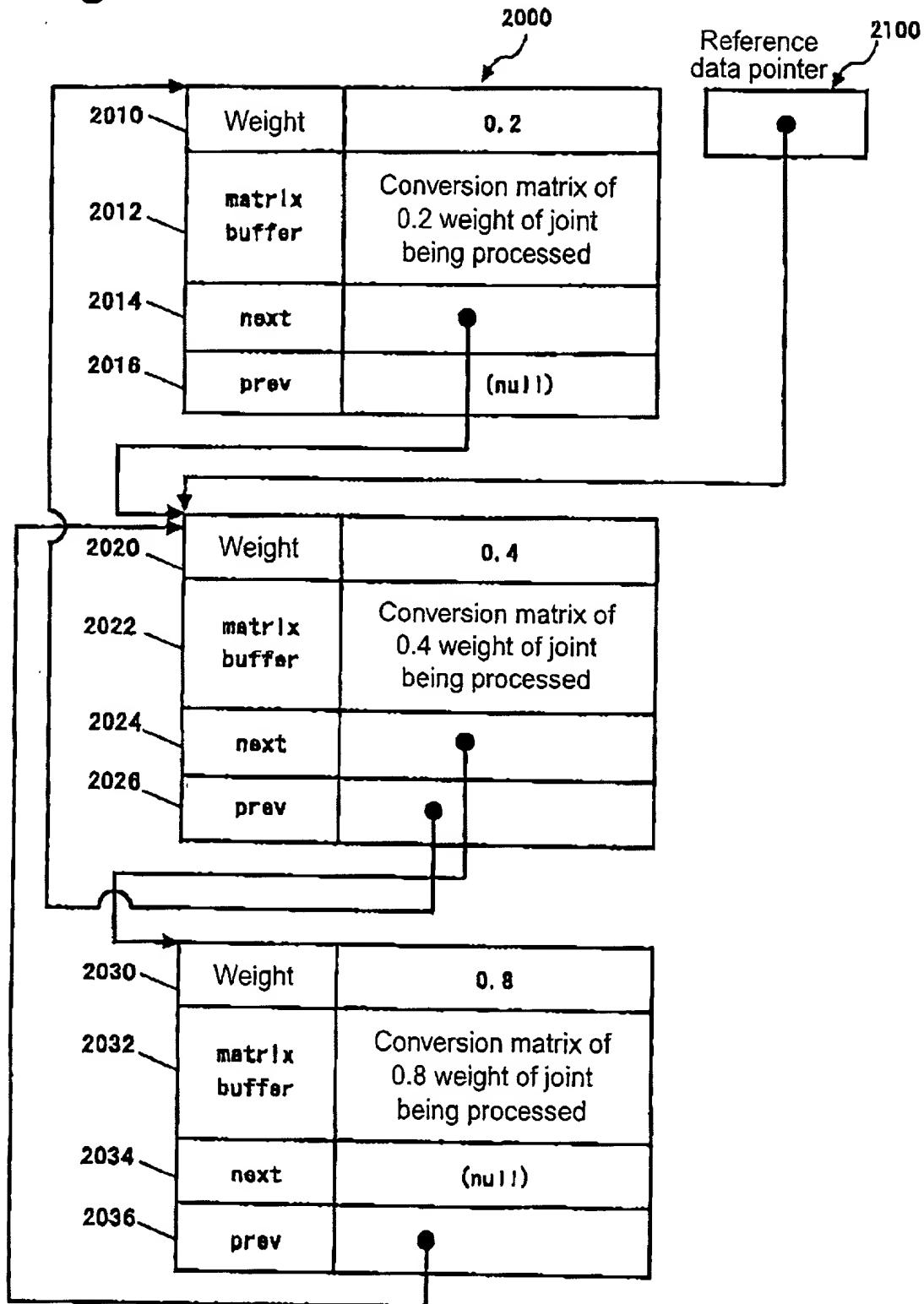
Weight	Weight
matrix buffer	Conversion matrix according to weight of joint being processed

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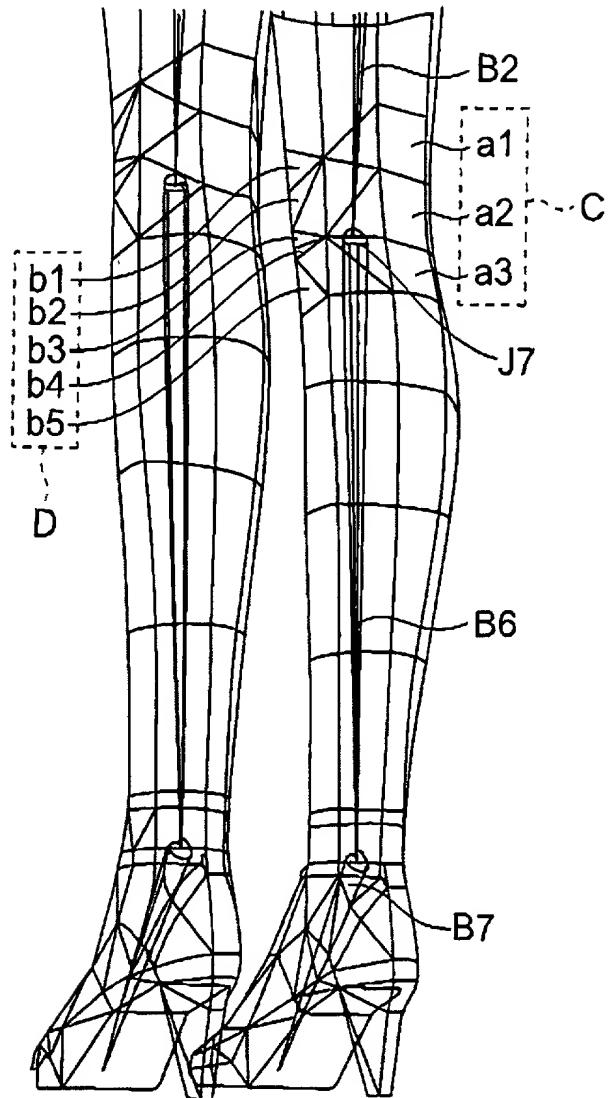
Fig.16

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Fig.17

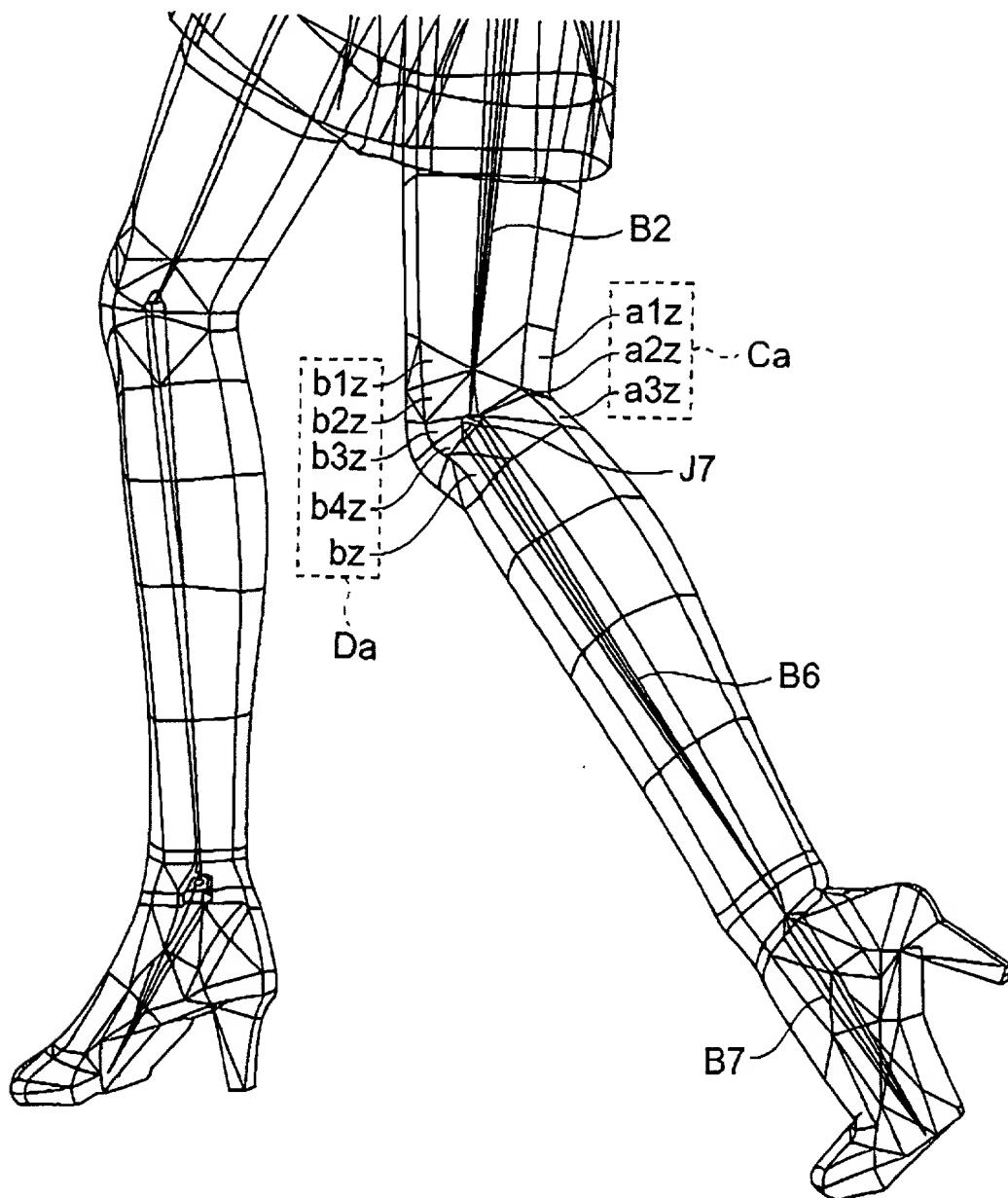


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Fig.18

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Fig. 19



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Fig.20

120

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Fig.21